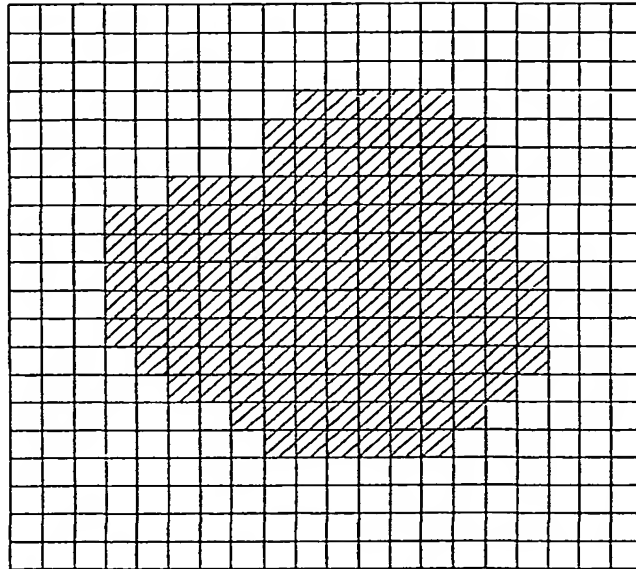


FIG. 1

(a) THREE-DIMENSIONAL BIT-MAP



(b) SOLID SHAPE DESCRIBING METHOD
OF THE PRESENT INVENTION

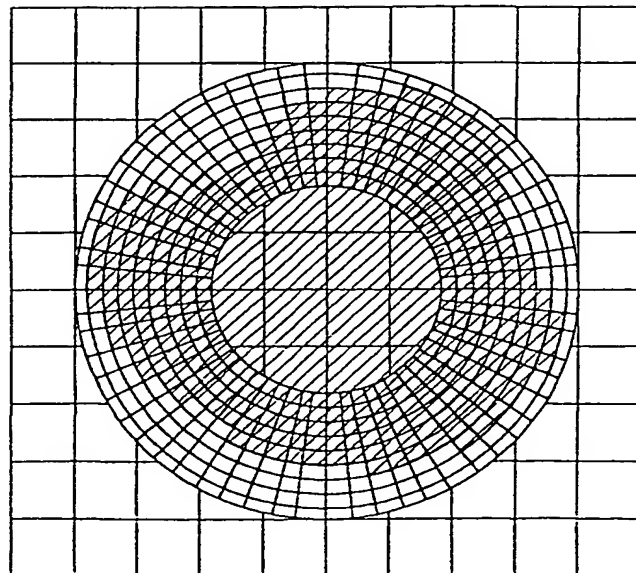


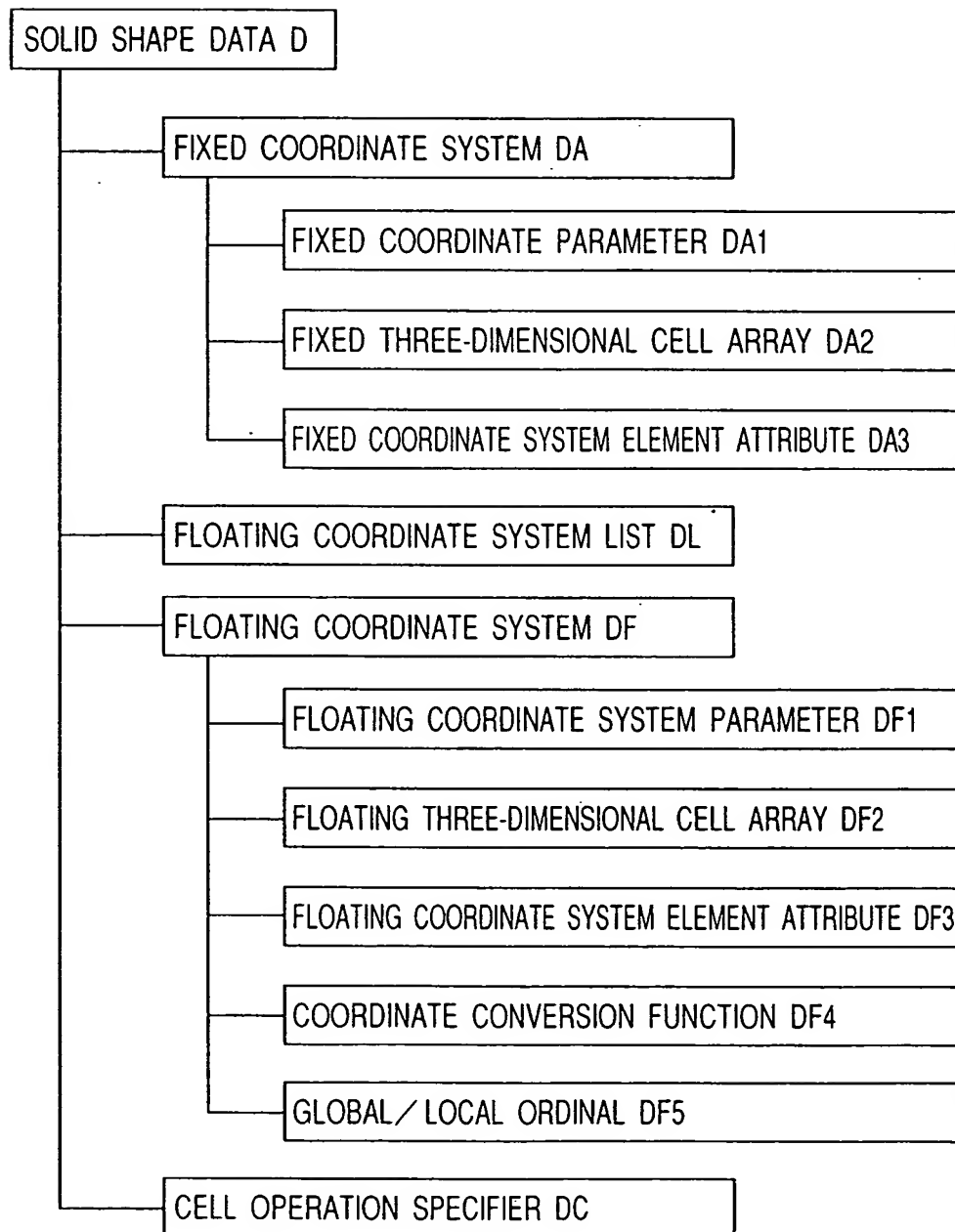
FIG. 2

FIG. 3

COORDINATE PARAMETERS

$$\boxed{r} \quad \boxed{\theta}$$

THREE-DIMENSIONAL CELL ARRAY

1	1	1	1	1	1	1	1	1	1	...	1	1	1
1	1	1	1	1	1	1	1	1	1	...	1	1	1
1	1	1	1	1	1	1	1	1	1	...	1	1	1
1	1	1	1	1	1	1	1	1	1	...	1	1	1
1	1	1	1	1	1	1	1	1	1	...	0	1	1
1	1	1	1	1	1	1	1	1	0	...	0	0	0
0	0	0	1	1	1	1	1	0	0	...	0	0	0
0	0	0	0	0	0	0	0	0	0	...	0	0	0

COORDINATE CONVERSION FUNCTIONS

$$X(r, \theta) = r \cos \theta$$

$$Y(r, \theta) = r \sin \theta$$

SOLID SHAPE

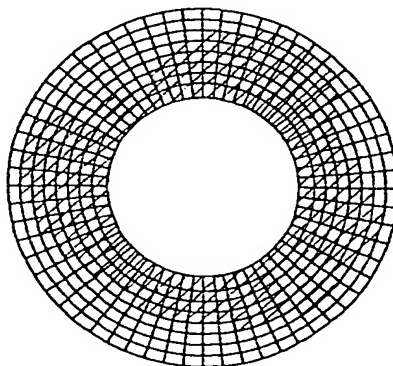


FIG. 4

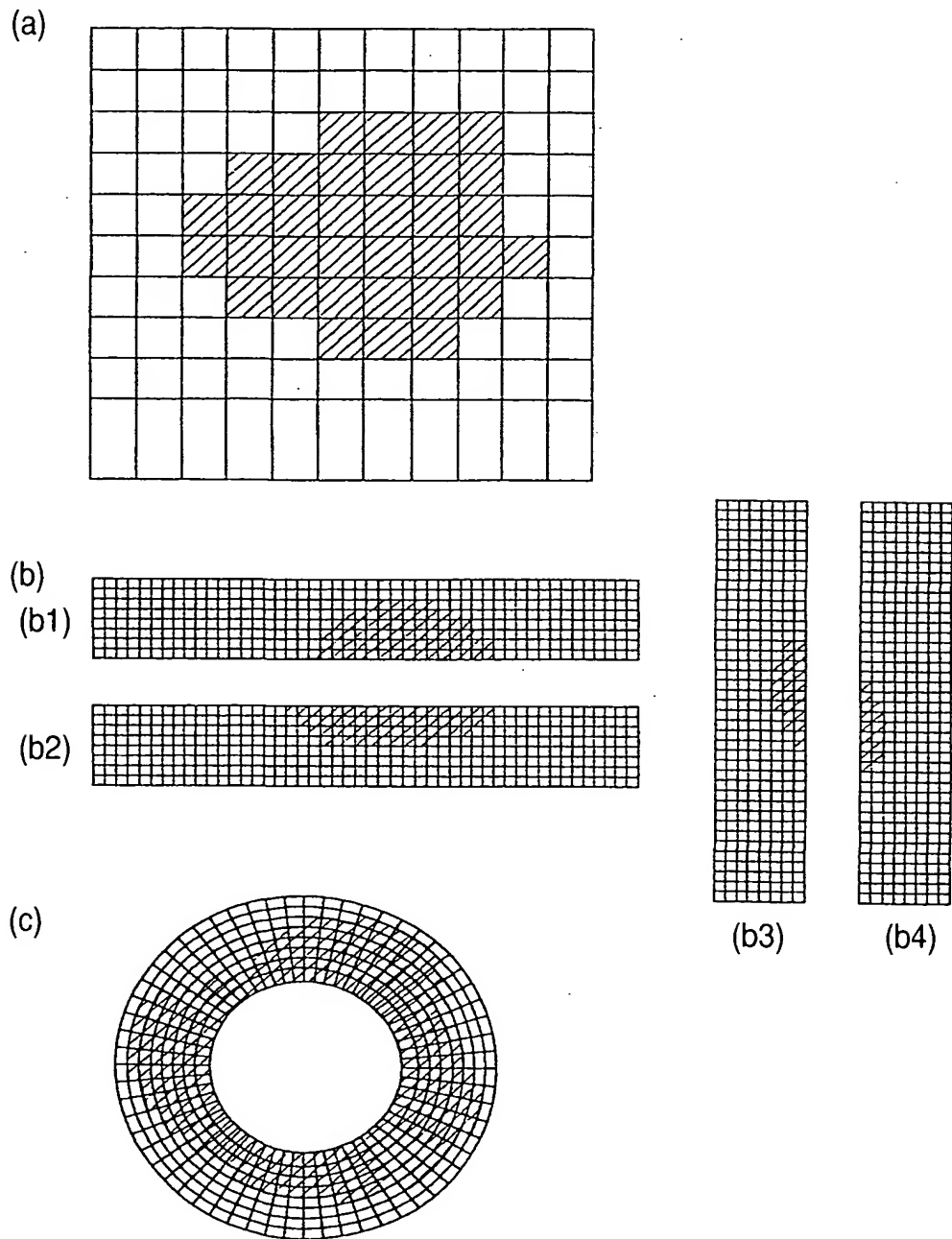
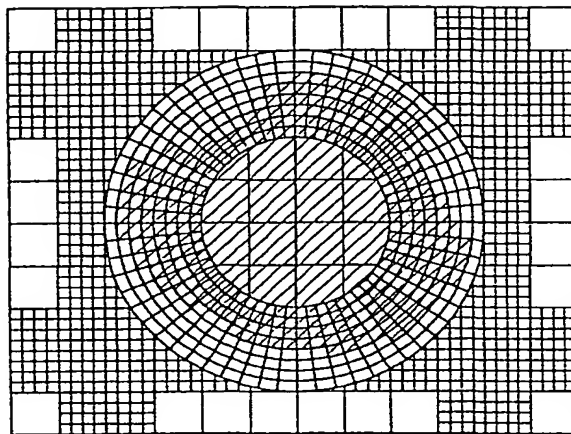


FIG. 5

(d)



(e)

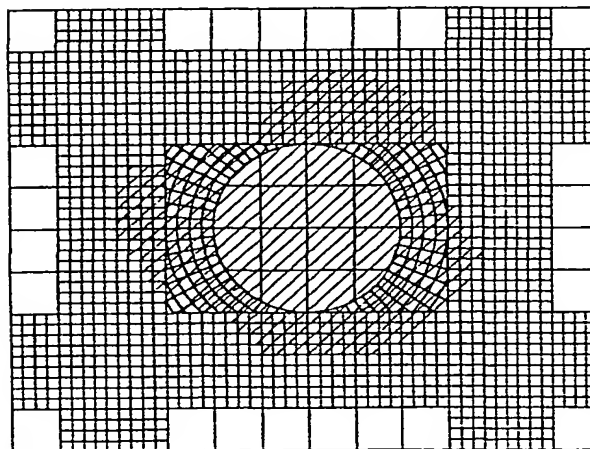


FIG. 6

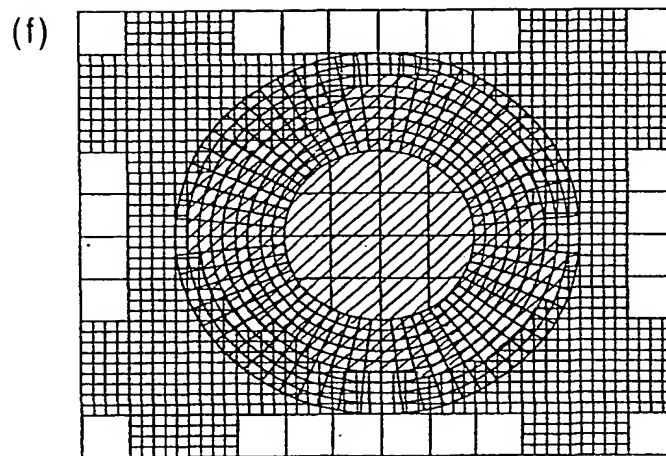


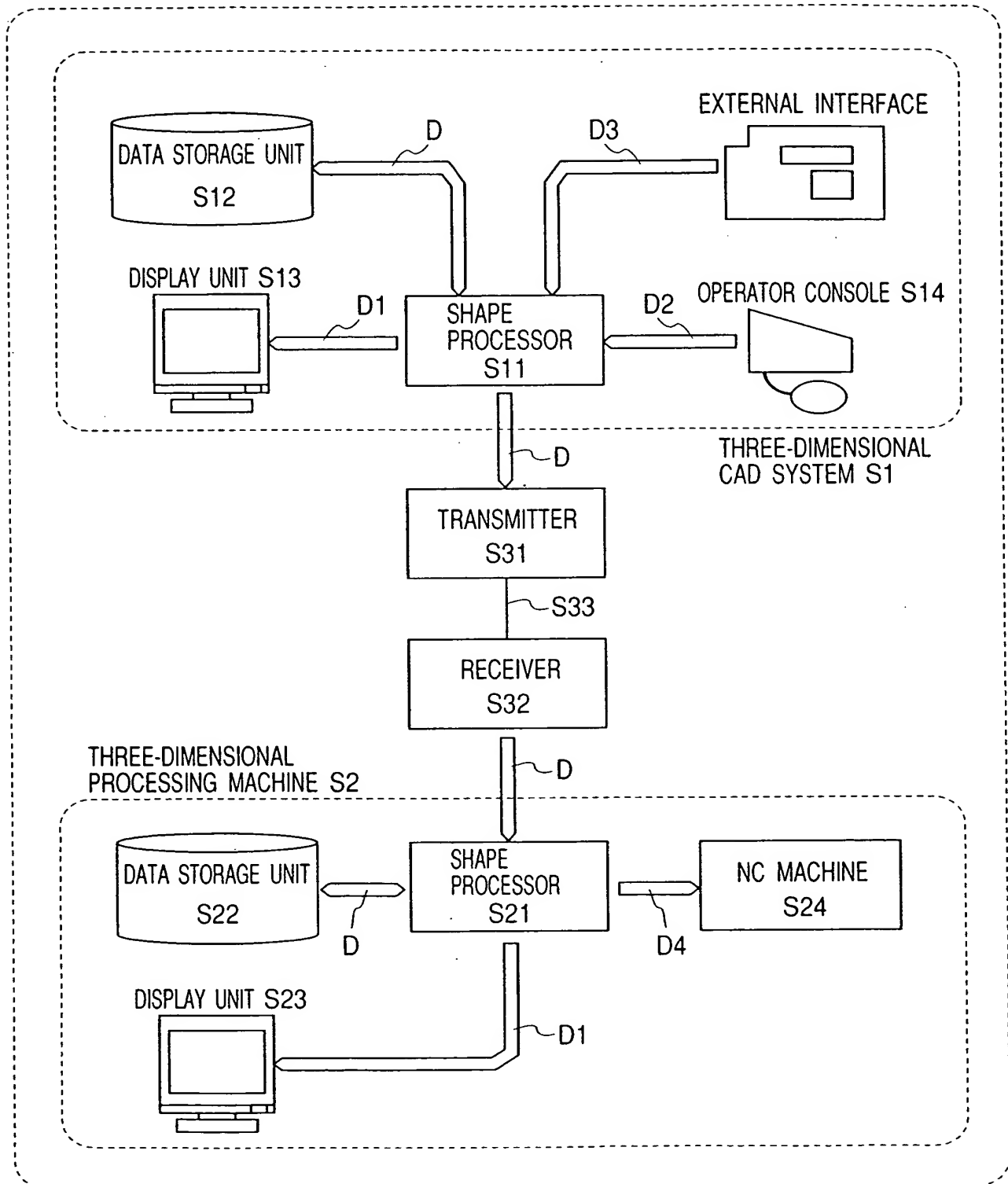
FIG. 7**SOLID SHAPE REMOTE PROCESSING SYSTEM SA**

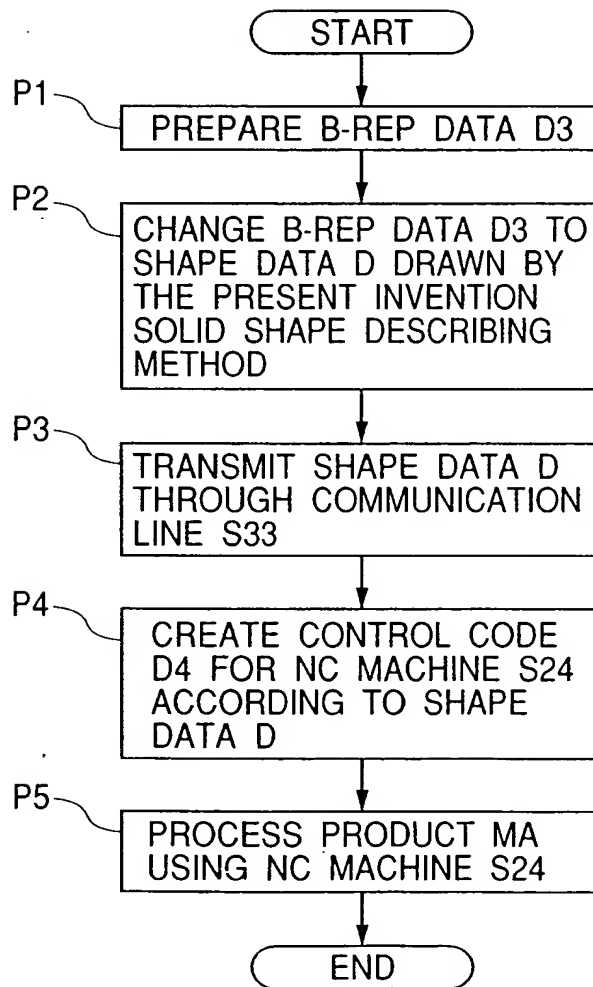
FIG. 8

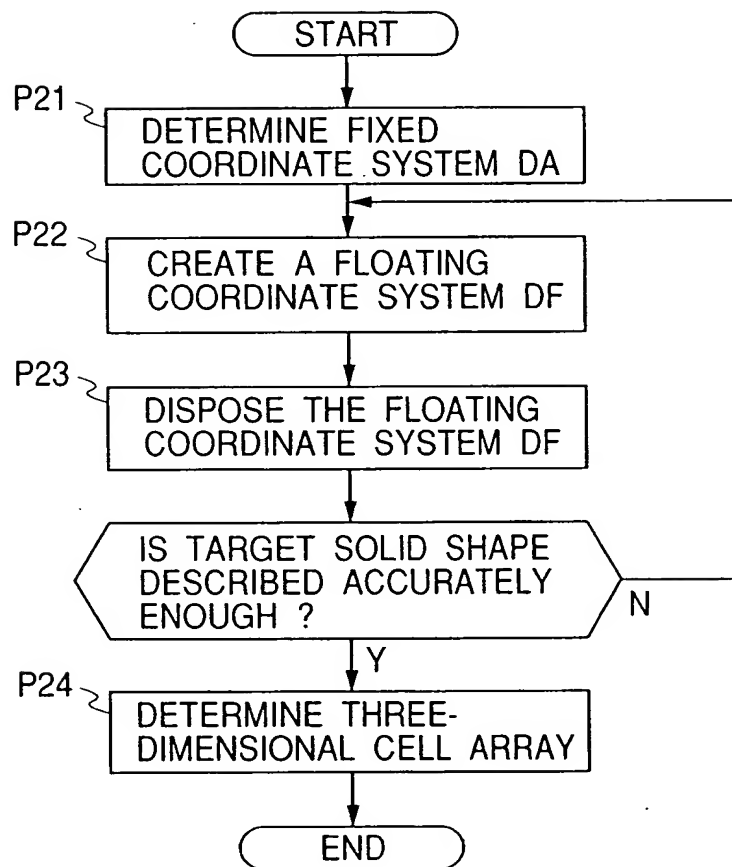
FIG. 9

FIG. 10

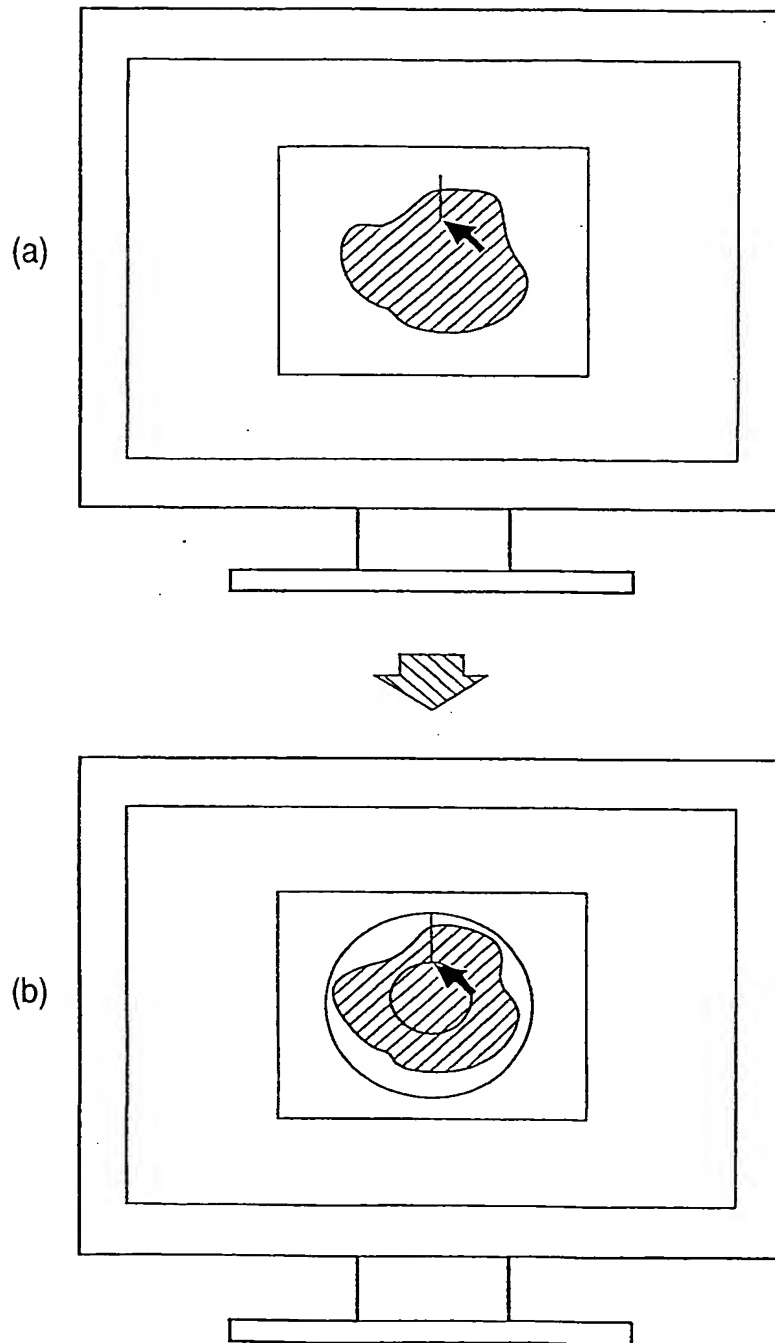


FIG. 11

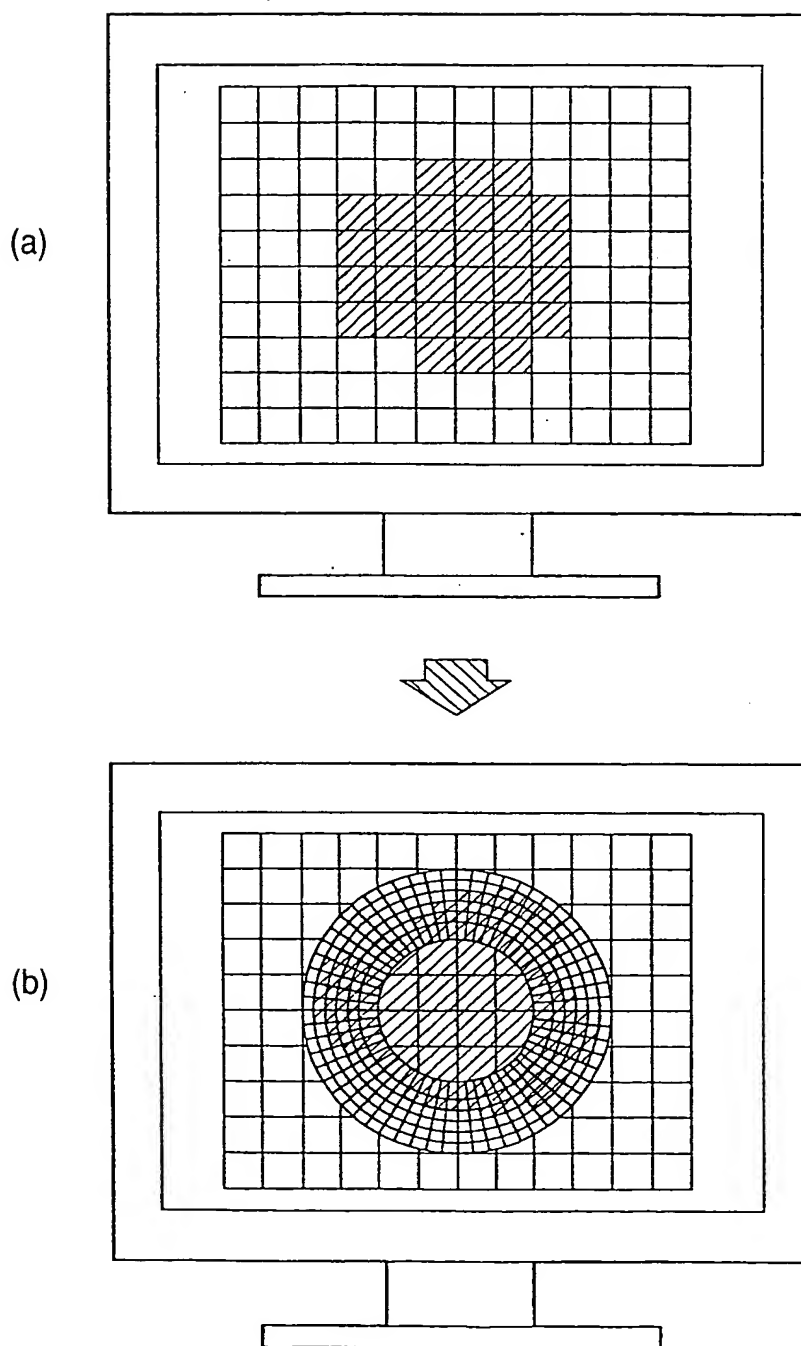
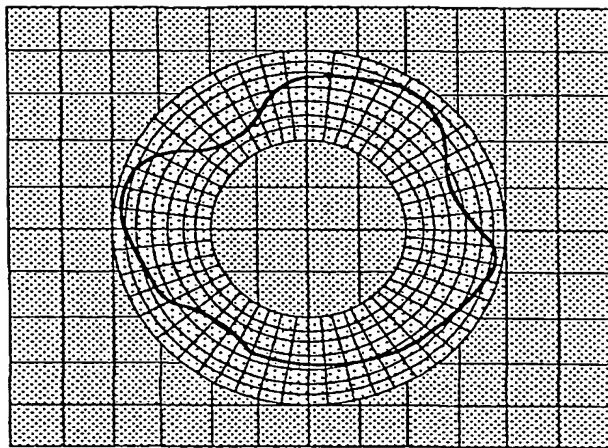


FIG. 12

(a)



(b)

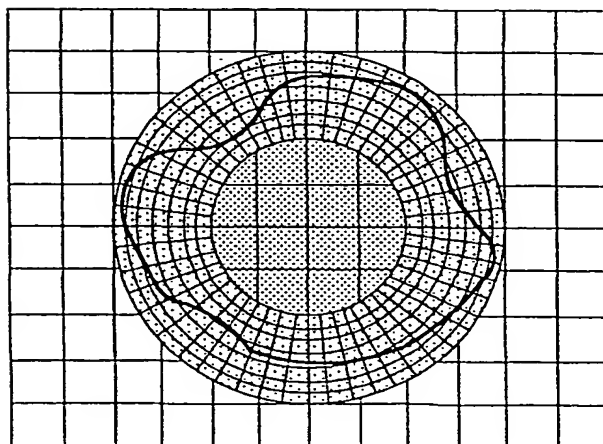


FIG. 13

(c)

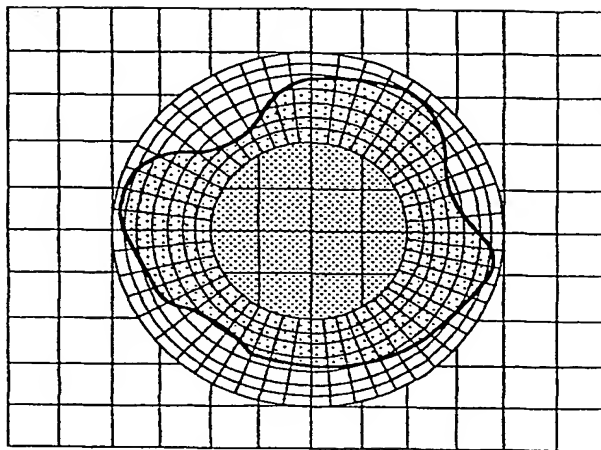


FIG. 14

SOLID SHAPE CAD CAM SYSTEM SB

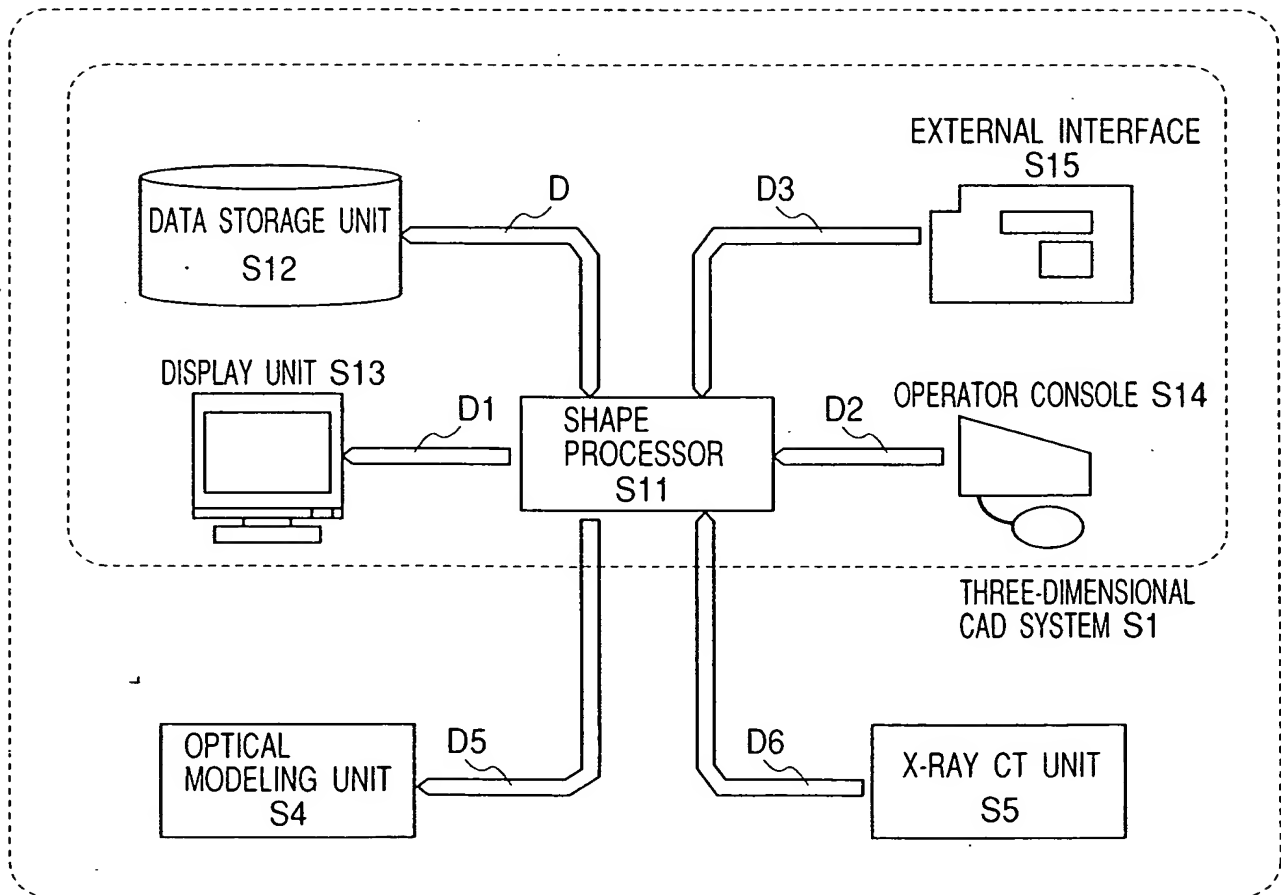


FIG. 15

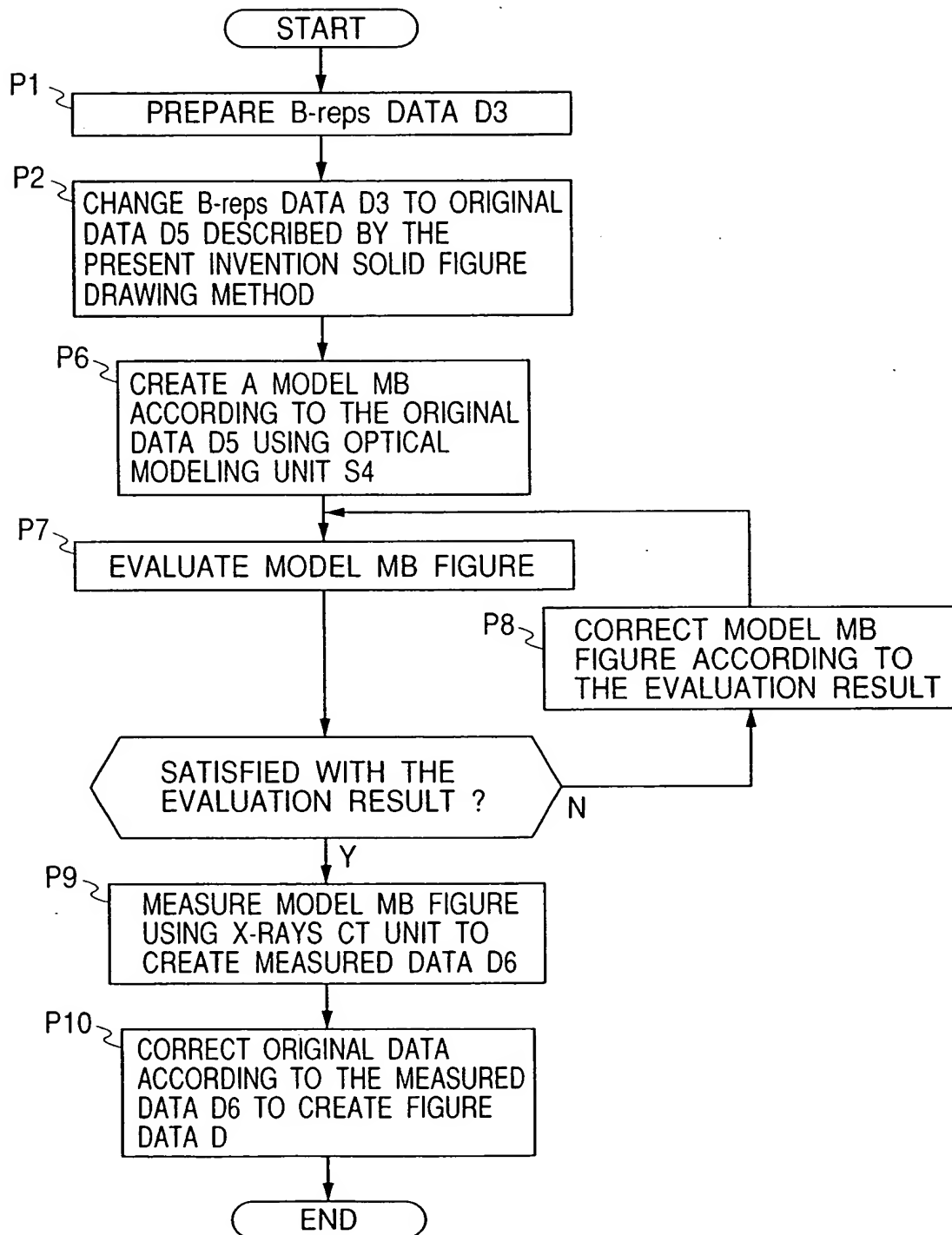


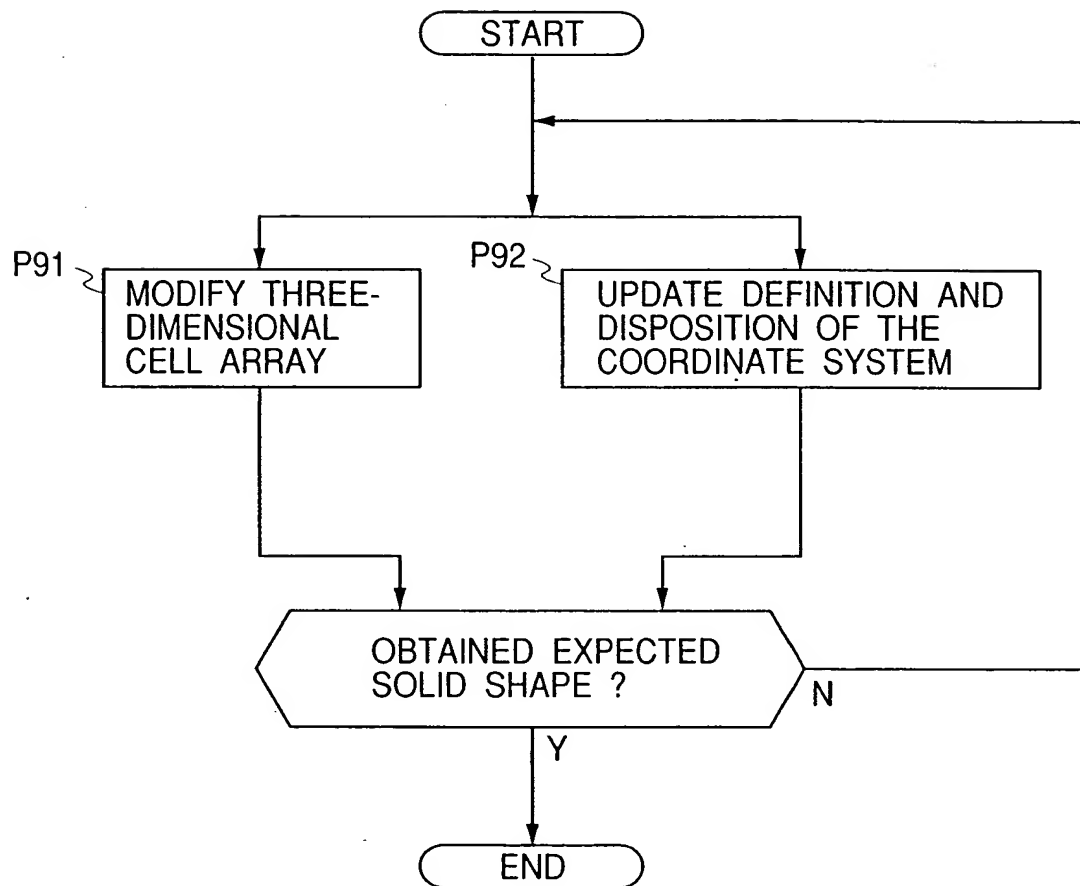
FIG. 16

FIG. 17

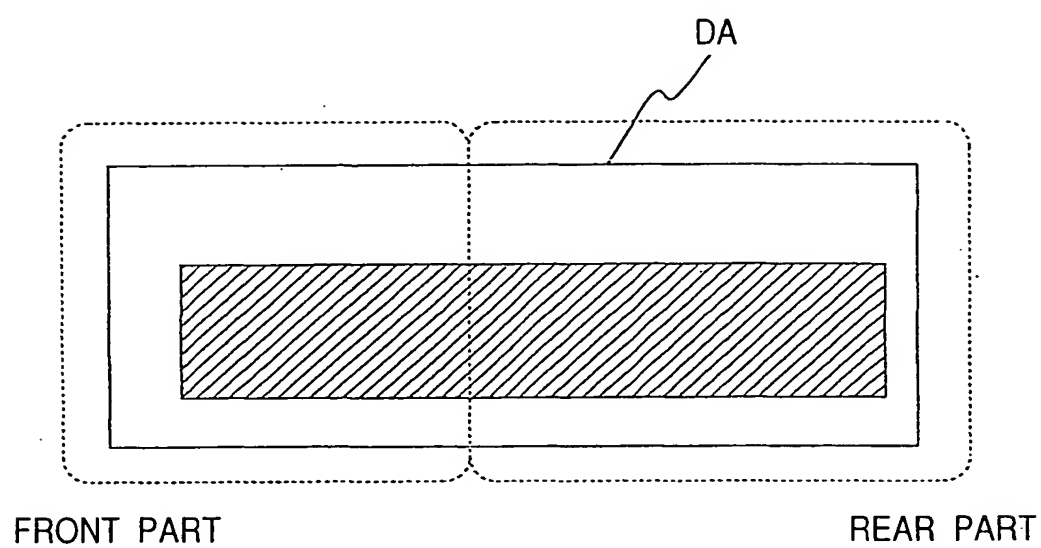
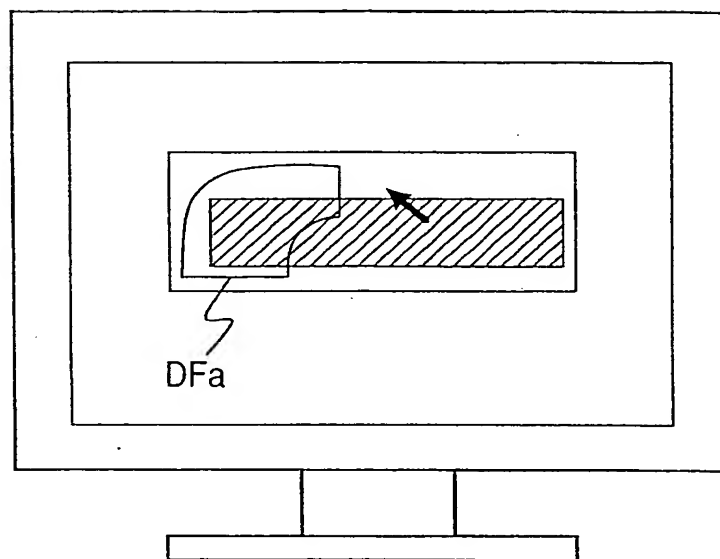


FIG. 18

(a)



(b)

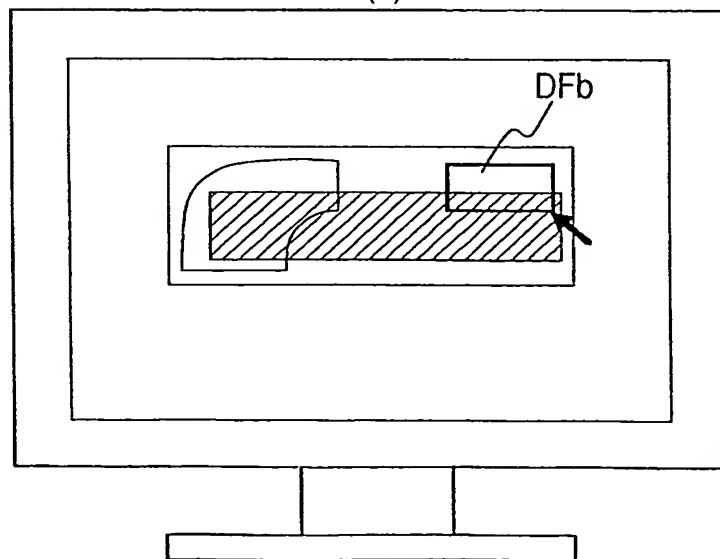
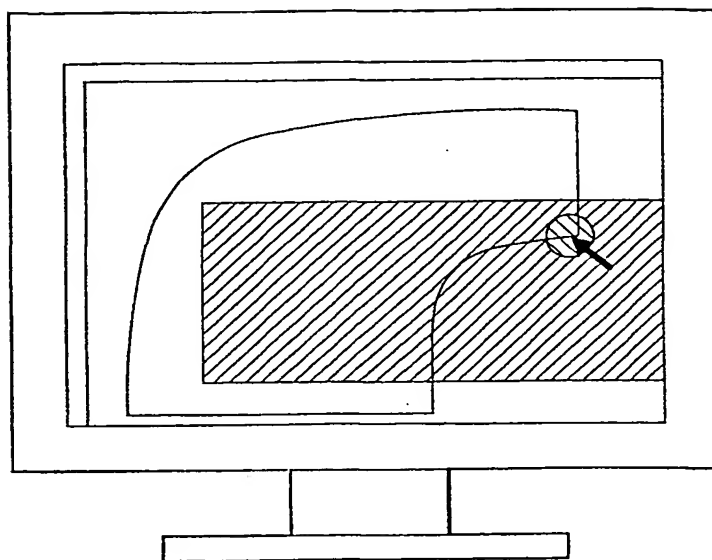


FIG. 19

(a)



(b)

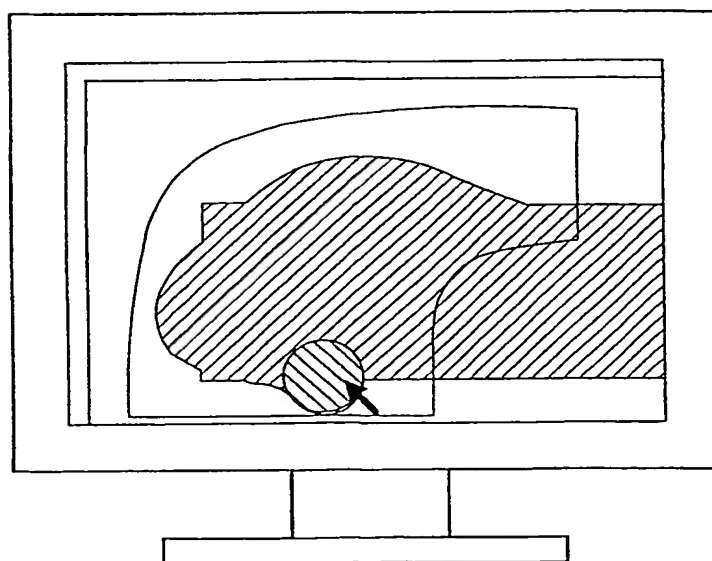
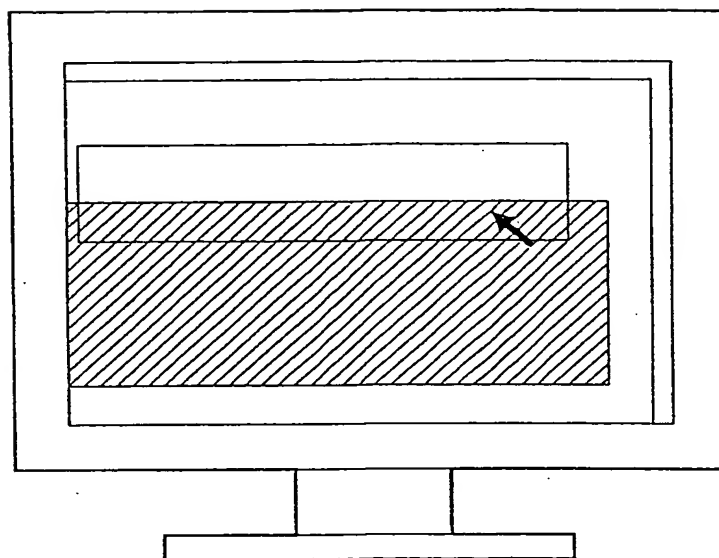


FIG. 20

(a)



(b)

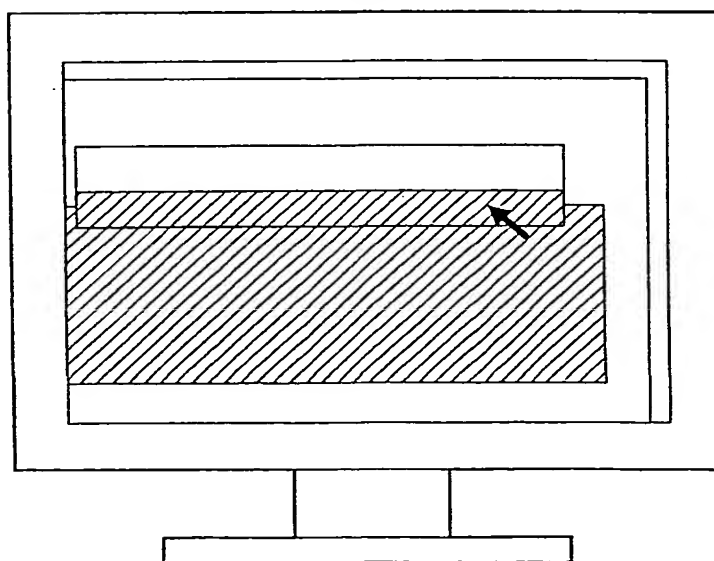


FIG. 21

